



ELSEVIER

Robotics and Autonomous Systems 29 (1999) 285–286

Robotics and
Autonomous
Systems

www.elsevier.com/locate/robot

Author Index to Volume 29

- | | | | |
|---|-----|---|-----|
| Aiyama, Y., M. Hara, T. Yabuki, J. Ota and T. Arai,
Cooperative transportation by two four-legged
robots with implicit communication | 13 | Fujita, M., H. Kitano and K. Kageyama, A reconfig-
urable robot platform | 119 |
| Allotta, B., <i>see</i> Conticelli, F. | 243 | García, J.J., <i>see</i> Ureña, J. | 269 |
| Arai, T., <i>see</i> Aiyama, Y. | 13 | Garelli, F., <i>see</i> Pagello, E. | 65 |
| Arai, Y., T. Fujii, H. Asama, H. Kaetsu and I. Endo,
Collision avoidance in multi-robot systems based
on multi-layered reinforcement learning | 21 | Haigh, K.Z. and M.M. Veloso, Learning situation-
dependent costs: Improving planning from prob-
abilistic robot execution | 145 |
| Asada, M. and H. Kitano, The RoboCup Challenge
(Keynote Introduction) | 3 | Han, K., <i>see</i> Veloso, M. | 133 |
| Asama, H., <i>see</i> Arai, Y. | 21 | Hara, M., <i>see</i> Aiyama, Y. | 13 |
| Bazaz, S.A. and B. Tondu, Minimum time on-line
joint trajectory generator based on low order
spline method for industrial manipulators | 257 | Hernández, Á., <i>see</i> Ureña, J. | 269 |
| Bison, P., G. Chemello, C. Sossai and G. Trainito,
Using a structured beacon for cooperative position
estimation | 33 | Huber, E., <i>see</i> Wasson, G. | 175 |
| Bueno, E., <i>see</i> Ureña, J. | 269 | Huber, S.A., M.O. Franz and H.H. Bülthoff, On
robots and flies: Modeling the visual orientation
behavior of flies | 227 |
| Bülthoff, H.H., <i>see</i> Huber, S.A. | 227 | Ijspeert, A.J., <i>see</i> Martinoli, A. | 51 |
| Chemello, G., <i>see</i> Bison, P. | 33 | Johansson, R., <i>see</i> Nilsson, K. | 205 |
| Colombo, C., <i>see</i> Conticelli, F. | 243 | Kaetsu, H., <i>see</i> Arai, Y. | 21 |
| Conticelli, F., B. Allotta and C. Colombo, Hybrid vi-
sual servoing: A combination of nonlinear control
and linear vision | 243 | Kageyama, K., <i>see</i> Fujita, M. | 119 |
| D'Angelo, A., <i>see</i> Pagello, E. | 65 | Kitano, H., <i>see</i> Asada, M. | 3 |
| Dillmann, R., <i>see</i> Friedrich, H. | 41 | Kitano, H., <i>see</i> Fujita, M. | 119 |
| Endo, I., <i>see</i> Arai, Y. | 21 | Knoll, A., <i>see</i> Zhang, J. | 91 |
| Ferrari, C., <i>see</i> Pagello, E. | 65 | Kokaji, S., <i>see</i> Yoshida, E. | 79 |
| Franz, M.O., <i>see</i> Huber, S.A. | 227 | Kortenkamp, D., <i>see</i> Wasson, G. | 175 |
| Friedrich, H., O. Rogalla and R. Dillmann, Commu-
nication and propagation of action knowledge in
multi-agent systems | 41 | Kurokawa, H., <i>see</i> Yoshida, E. | 79 |
| Fujii, T., <i>see</i> Arai, Y. | 21 | Martinoli, A., A.J. Ijspeert and F. Mondada, Un-
derstanding collective aggregation mechanisms:
From probabilistic modelling to experiments with
real robots | 51 |
| | | Matarić, M.J., <i>see</i> Michaud, F. | 187 |
| | | Mazo, M., <i>see</i> Ureña, J. | 269 |
| | | Michaud, F. and M.J. Matarić, Representation of
behavioral history for learning in nonstationary
conditions | 187 |

- | | | | |
|---|-----|--|-----|
| Mondada, F., <i>see</i> Martinoli, A. | 51 | Ureña, J., M. Mazo, J.J. García, Á. Hernández and E. Bueno, Classification of reflectors with an ultrasonic sensor for mobile robot applications | 269 |
| Montesello, F., <i>see</i> Pagello, E. | 65 | | |
| Murata, S., <i>see</i> Yoshida, E. | 79 | | |
| Nilsson, K. and R. Johansson, Integrated architecture for industrial robot programming and control | 205 | Veloso, M., P. Stone and K. Han, The CMUnited-97 robotic soccer team: Perception and multi-agent control | 133 |
| Ota, J., <i>see</i> Aiyama, Y. | 13 | Veloso, M.M., <i>see</i> Haigh, K.Z. | 145 |
| Pagello, E., A. D'Angelo, F. Montesello, F. Garelli and C. Ferrari, Cooperative behaviors in multi-robot systems through implicit communication | 65 | von Collani, Y., <i>see</i> Zhang, J. | 91 |
| Rogalla, O., <i>see</i> Friedrich, H. | 41 | Wasson, G., D. Kortenkamp and E. Huber, Integrating active perception with an autonomous robot architecture | 175 |
| Sossai, C., <i>see</i> Bison, P. | 33 | Yabuki, T., <i>see</i> Aiyama, Y. | 13 |
| Stone, P., <i>see</i> Veloso, M. | 133 | Yamauchi, B., Decentralized coordination for multi-robot exploration | 111 |
| Sukhatme, G.S., Intelligent embodied autonomous agents (Editorial) | 109 | Yoshida, E., S. Murata, K. Tomita, H. Kurokawa and S. Kokaji, An experimental study on a self-repairing modular machine | 79 |
| Tomita, K., <i>see</i> Yoshida, E. | 79 | | |
| Tondu, B., <i>see</i> Bazaz, S.A. | 257 | Zhang, J., Y. von Collani and A. Knoll, Interactive assembly by a two-arm robot agent | 91 |
| Trainito, G., <i>see</i> Bison, P. | 33 | | |



ELSEVIER

Robotics and Autonomous Systems 29 (1999) 287–288

**Robotics and
Autonomous
Systems**

www.elsevier.com/locate/robot

Subject Index to Volume 29

Agent architecture	175	Map-building	111
Autonomous agents	227	Markers	175
Autonomous industrial robots	205	Minimum time trajectory	257
		Mobile robot	21, 111, 269
Behavior-based representation	187	Mobile robot cooperation	33
		Mobile robot pose estimation	33
Clustering	51	Modelling	51
Cognition architecture	91	Multi-agent coordination	111
Collaborative behavior	133	Multi-agent robotic systems	133
Collective autonomous robotics	51	Multi-agents systems	41
Collision avoidance	21	Multi-layered learning	21
Cooperation	13	Multi-robots	65
		Multi-robot experiments	187
Data fusion	33	Multi-robot teams	111
Distributed autonomous systems	79	Multiple sensor/actor systems	91
Emergent behaviors	65	Nonstationary conditions	187
Exploration	111	Object fixation	227
		On-line motion	257
Fly behavior	227	OPEN-R	119
Grand challenge	3	Perceptual memory	175
		Planner-independent learning	145
Homogeneous modular machine	79	Polynomials	257
Human–robot interface	91	Possibilistic logic	33
		Proximity space	175
Implicit communication	13, 65	Quadruped robot	119
Industrial manipulator	257		
Integration of planning and execution	145	Real robots	51
Intelligent sensor	269	Reasoning with uncertainty	33
		Reconfigurable robot platform	119
Kinematic constraints	257	Reflector discrimination	269
Knowledge representation	41	Reinforcement learning	21
		RoboCup	3, 65
Landmark project	3	Robot control architecture	205
Learning	41	Robot coordination	65
Learning from real execution	145	Robot entertainment	119
Legged robot	13	Robot learning	187
Local communication	21	Robot simulation	51

Robot soccer	3	Sensorimotor control	227
Robot world cup	3	Skill learning	91
Robotic soccer	133	Stereo vision	175
Rule based control	13	Ultrasonic sensor	269
Self-assembly	79	Visual information processing	227
Self-evaluation of performance	187	Wheel-based robot	119
Self-repair	79		
Sensor-based control	91		

